

In the Claims:

Please amend the claims as follows:

1. (currently amended) An industrial robot, comprising:

a first part;

a second part, wherein the first part and the second part are arranged to be movable with respect to each other;

a first ~~contact/securing~~ cable connection/securing point arranged on the first part;

a second ~~contact/securing~~ cable connection/securing point arranged the second part;

at least one cable secured to at least one of the first cable connection/securing point and the second cable connection/securing point and releasably connected to at least one of the first cable connection/securing point and the second cable connection/securing point, the at least one cable extending freely from the first ~~contact/securing~~ cable connection/securing point to the second ~~contact/securing~~ cable connection/securing point; and

an internal cavity, wherein the first ~~contact/securing~~ cable connection/securing point and the second ~~contact/securing~~ cable connection/securing point are arranged in the internal cavity, and wherein an excess of the at least one cable extends freely through the internal cavity from the first ~~contact/securing~~ cable connection/securing point to the second ~~contact/securing~~ cable connection/securing point such that as the first part and the second part move relative to each other, the internal cavity accommodates the excess of cable moving back and forth between slack and tension.

2. (previously amended) The robot according to claim 1, wherein one of said first part and said second part rotates or pivots about another of the first part and the second part.

3. (previously amended) The robot according to claim 1, wherein one of the first part and the second part comprises an electric motor.

4. (previously amended) The robot according to claim 1, wherein said excess of cable forms an arch inside the internal cavity.

5. (previously amended) The robot according to claim 1, wherein said excess of cable forms a spiral inside the internal cavity.

6. (previously amended) The robot according to claim 1, wherein said excess of cable forms an S-shape inside the internal cavity.

7. (previously amended) The robot according to claim 6, wherein the excess of cable extends along an inner wall of the internal cavity.

8. (currently amended) A method of connecting at least part of at least one cable between a first part and a second part of an industrial robot which are arranged to be movable with respect to each other, wherein said at least one cable extends from a first ~~contact/securing~~ cable connection/securing point on the first part to a second ~~contact/securing~~ cable connection/securing point on the second part via an internal cavity, wherein the first

~~contact/securing cable connection/securing point~~ and the second ~~contact/securing cable connection/securing point~~ are located in the internal cavity, the method comprising:

~~connecting/securing a first end of~~ said at least one cable ~~releasably to at least one of the first contact/securing cable connection/securing point and the second cable connection/securing point,~~

moving the first cable connection/securing point and second ~~contact/securing points cable connection/securing point~~ into a position where they are furthest from each other,

extending a length of cable freely through the internal cavity from the first ~~contact/securing cable connection/securing point~~ to the second ~~contact/securing cable connection/securing point~~, and

releasably connecting/securing a second end of said at least one cable ~~releasably to the second part at least one of the first cable connection/securing point and the second cable connection/securing point.~~

9. (currently amended) The method according to claim 8, further comprising:

rotating or pivoting the first part and the second part about another of the first part and the second part, thereby increasing or decreasing a rotary tension on the cable with respect to the first ~~contact/securing cable connection/securing point~~ and the second ~~contact/securing cable connection/securing point~~, wherein the internal cavity accommodates a slackening of the length of cable as the rotary tension on the cable increases or decreases.

10. (previously presented) The method according to claim 9, wherein said excess of cable forms an arch inside the internal cavity when the rotary tension on the cable increases or

decreases.

11. (previously presented) The method according to claim 9, wherein said excess of cable forms a spiral inside the internal cavity when the rotary tension on the cable increases or decreases.

12. (previously presented) The method according to claim 9, wherein said excess of cable forms an S-shape inside the internal cavity when the rotary tension on the cable increases or decreases.

13. (previously presented) The method according to claim 9, wherein the excess of cable extends along an inner wall of the internal cavity when the rotary tension on the cable increases or decreases.

14. (currently amended) The industrial robot according to claim 1, wherein the first ~~contact/securing~~ cable connection/securing point comprises a first releasable contact operatively connected to the first part.

15. (currently amended) The industrial robot according to claim 1, wherein the second ~~contact/securing~~ cable connection/securing point comprises a second releasable contact operatively connected to the second part.

16. (currently amended) The industrial robot according to claim 1, wherein the first

~~contact/securing~~ cable connection/securing point comprises a first releasable contact operatively connected to the first part, and wherein the second ~~contact/securing~~ cable connection/securing point comprises a second releasable contact operatively connected to the second part.

17. (previously presented) The industrial robot according to claim 1, wherein the at least one cable transmits electricity, an electric signal, an optic signal, or a substance.

18. (currently amended) A method of operating an industrial robot, comprising a first part, a second part, wherein the first part and the second part are arranged to be movable with respect to each other, a first ~~contact/securing~~ cable connection/securing point arranged on the first part, a second ~~contact/securing~~ cable connection/securing point arranged on the second part, at least one cable extending from the first ~~contact/securing~~ cable connection/securing point to the second ~~contact/securing~~ cable connection/securing point; and an internal cavity, wherein the first ~~contact/securing~~ cable connection/securing point and the second ~~contact/securing~~ cable connection/securing point are located in the internal cavity, and wherein an excess of the at least one cable extends freely through the internal cavity from the first ~~contact/securing~~ cable connection/securing point to the second ~~contact/securing~~ cable connection/securing point, the method comprising:

moving the first part and the second part relative to each other, thereby moving the excess of cable within the internal cavity back and forth between slack and tension, wherein the internal cavity accommodates the excess of cable moving back and forth between slack and tension.

19. (currently amended) An industrial robot, comprising:

a first part;

a second part, wherein the first part and the second part are arranged to be movable with respect to each other;

a releasable contact point arranged on one of the first part or the second part;

a securing point arranged on another of the first part or the second part;

at least one cable extending from the contact point to the securing point; and

an internal cavity, wherein the contact point and the securing point are located in the internal cavity, and wherein an excess of the at least one cable extends freely through the internal cavity from the contact point to the securing point such that as the first part and the second part move relative to each other, the internal cavity accommodates the excess of cable moving back and forth between slack and tension.

20. (previously presented) The industrial robot according to claim 19, wherein the at least one cable transmits electricity, an electric signal, an optic signal, or a substance.

21. (currently amended) The robot according to claim 1, wherein the internal cavity is arranged in the vicinity of a joint between the first part and the second part, and wherein the cable extends from the first connection/securing point and the second connection/securing point between an entrance of the cable into the internal cavity and an exit of the cable from the internal cavity.